

ABSTRACT OF THE DISCLOSURE

An articulated robot capable of reducing dead space while maintaining a wide operating area and simplifying a power transmission system necessary for moving each joint. A plurality of joint arms A1 to A7 are connected via first rotating shafts 15, 15A, and 15B as horizontal rotating shafts and via second rotating shafts 32, 32A, and 32B as inclined rotating shafts alternately. A motor M for driving the rotating shaft and a speed-reducing mechanism are provided for each rotating shaft.